

✓ Please delete the paragraph beginning at page 6, line 11.

Please replace the paragraph beginning at page 7, line 11 with the following rewritten paragraph:

C, In this specification, identical or corresponding parts have identical or corresponding reference numerals. In this specification, a manipulator 1 is shown having a foot part 2, a first member 4, a second member 6, a third member 8 and a gripper 10. The gripper 10 is designed with, for instance, two or three fingers 12A, 12B that can be moved towards each other, but, if so desired, it may also be designed differently, for instance with snap means specifically adjusted to an object to be picked up or engaged otherwise, magnetic means, more or fewer fingers, and the like. In this specification, the first member 4 will be referred to as upper arm, the second member 6 will be referred to as lower arm and the third member 8 will be referred to as wrist. The foot part 2 is of substantially tubular design, as will be explained in more detail hereinbelow, and is connected, via a foot plate as shown in more detail in Fig. 10, to a base plate 14 for rotation about its longitudinal axis L, which base plate 14 can be directly connected to the fixed world or, for instance, to a constructional part 18 via a parallel arm construction 16, as shown in Fig. 1, to enable the manipulator 1 to be moved in vertical direction V. Of course, other types of suspension constructions can be used, enabling translating and/or rotating movements of the entire manipulator 1 in the desired directions.

Please replace the paragraph beginning at page 15, line 21 with the following rewritten paragraph:

C, --The pack of second shafts 170 comprises a seventh rotary shaft 174 provided with a seventh driving geared belt wheel 176 adjacent a first end thereof and fixedly connected, via an end plate 178, to the lower arm section 180 adjacent its opposite end. Hence, rotation of the